# Dynamic Control System Mode Performance of the Space Technology-7 Disturbance Reduction System

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Oscar Hsu
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#### Outline



Introduction

LISA Pathfinder/Disturbance Reduction System (DRS)
 Initial and Final Configuration

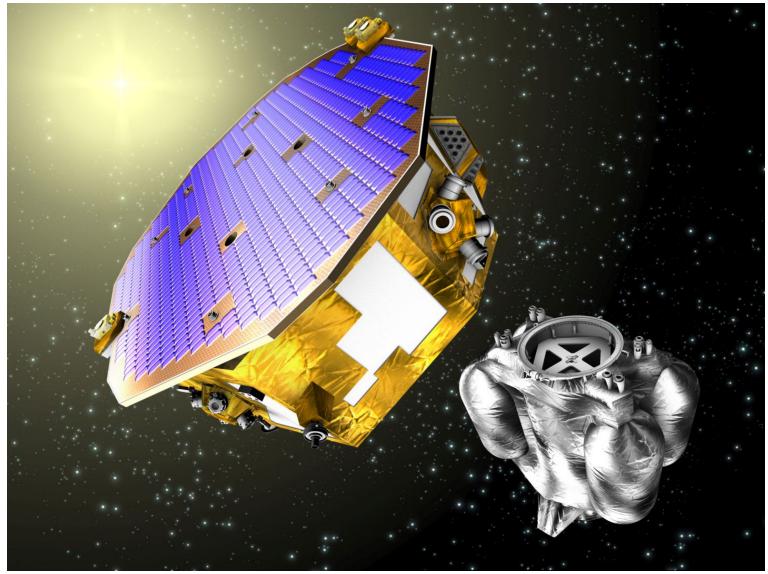
DRS Dynamic Control System (DCS) Mode Design

DCS Mode Performance

Conclusion and Acknowledgements

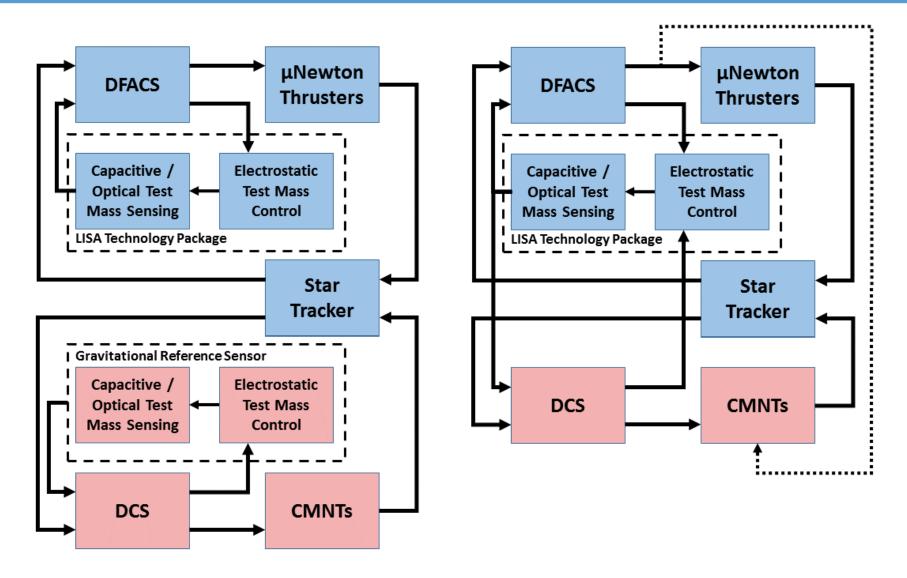
## Introduction





## LPF/DRS Initial and Final Configuration





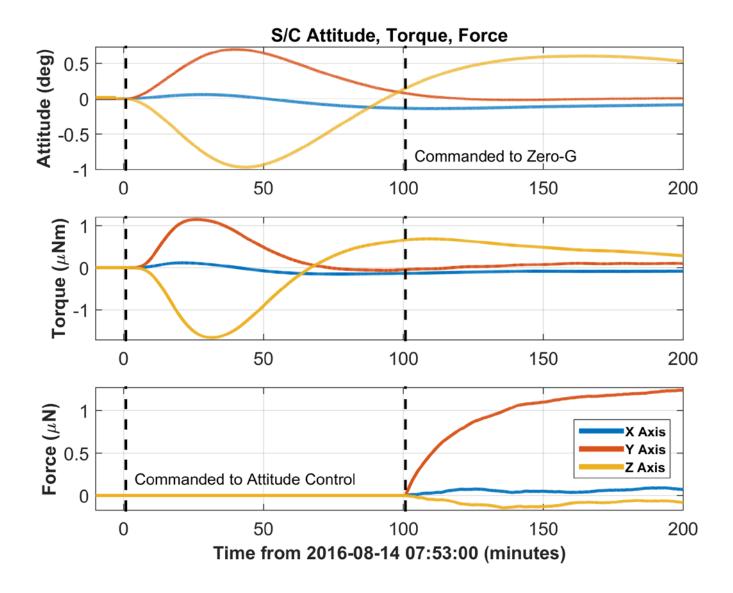
# DCS Control Mode Design



DRS Mission Mode	Spacecraft Control Mode	Reference Test Mass Control Mode	Reference Test Mass Force Mode	Non-Reference Test Mass Control Mode	Non-Reference Test Mass Force Mode
Standby	Standby	DFS Standby	N/A	DFS Standby	N/A
Attitude Control	Attitude-Only	DFS Accelerometer	High Force	DFS Accelerometer	High Force
Zero-G	Accelerometer				
Drag Free Low Force	Drag Free 1	DFS			
18-DOF Transitional		Drag Free 1	Low Force	Suspended Drag Free 1	Low Force
18-DOF	Science	DFS Drag Free 2		Suspended Drag Free 2	

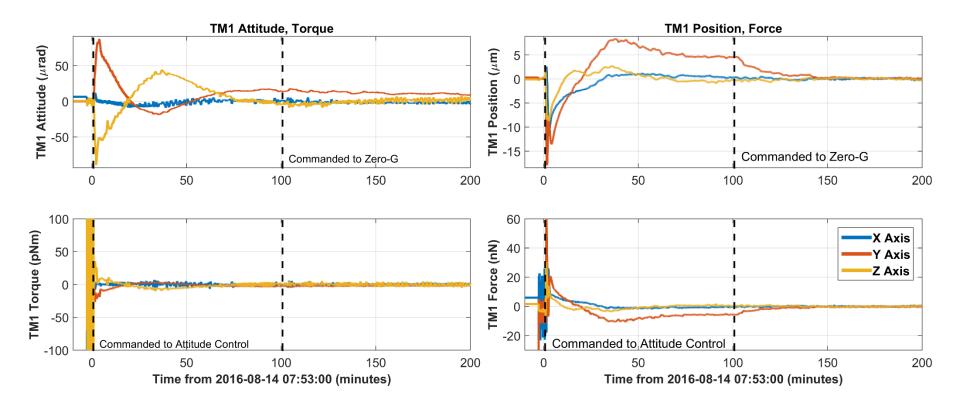
## Attitude Control and Zero-G: Spacecraft





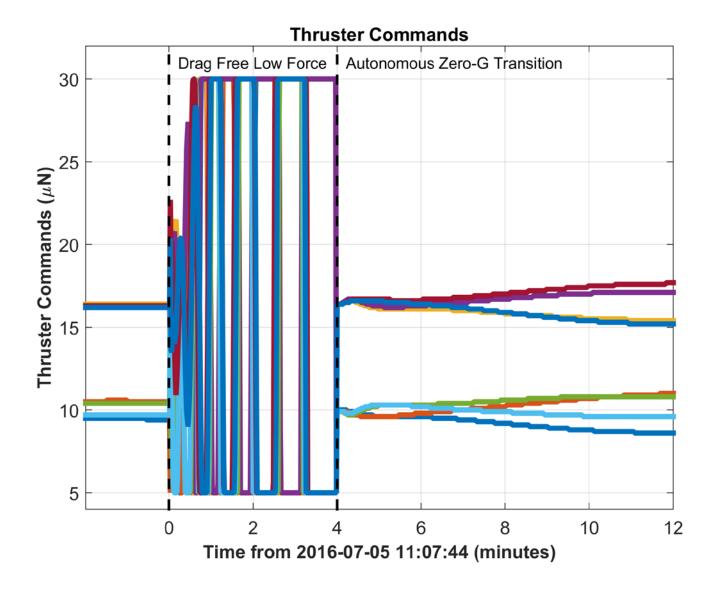
#### Attitude Control and Zero-G: Test Mass 1





### Initial Drag Free Low Force Test





# DCS Control Mode Design



DRS Mission Mode	Spacecraft Control Mode	Reference Test Mass Control Mode	Reference Test Mass Force Mode	Non-Reference Test Mass Control Mode	Non-Reference Test Mass Force Mode
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Attitude Control	Attitude-Only	DFS Accelerometer	High Force	DFS Accelerometer	High Force
Zero-G	Accelerometer				
Drag Free Low Force	Drag Free 1	DFS		High For	
18-DOF Transitional		Drag Free 1 Low Fo	Low Force	Suspended Drag Free 1	Low Force
18-DOF	Science	DFS Drag Free 2		Suspended Drag Free 2	

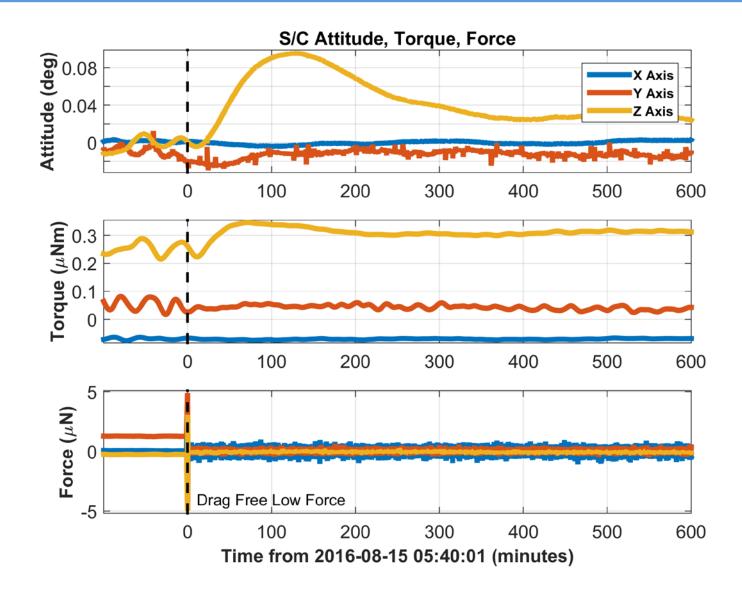
# Test Mass Control for Drag Free Transition



DRS Mission Mode	Spacecraft Control Mode	Reference Test Mass Control Mode	Reference Test Mass Force Mode	Non-Reference Test Mass Control Mode	Non-Reference Test Mass Force Mode
Standby	Standby	DFS Standby	N/A	DFS Standby	N/A
Attitude Control	Attitude-Only	DFS	High Force		
Zero-G	Accelerometer	Accelerometer		DFS Accelerometer	High Force
Drag Free Low Force	Drag Free 1	DFS			
18-DOF Transitional		Drag Free 1	Low Force	Suspended Drag Free 1	Low Force
18-DOF	Science	DFS Drag Free 2		Suspended Drag Free 2	

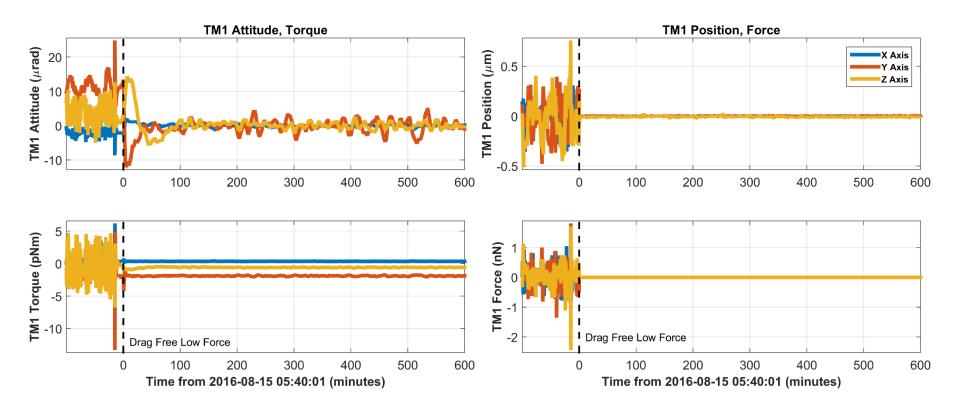
## Drag Free Low Force: Spacecraft





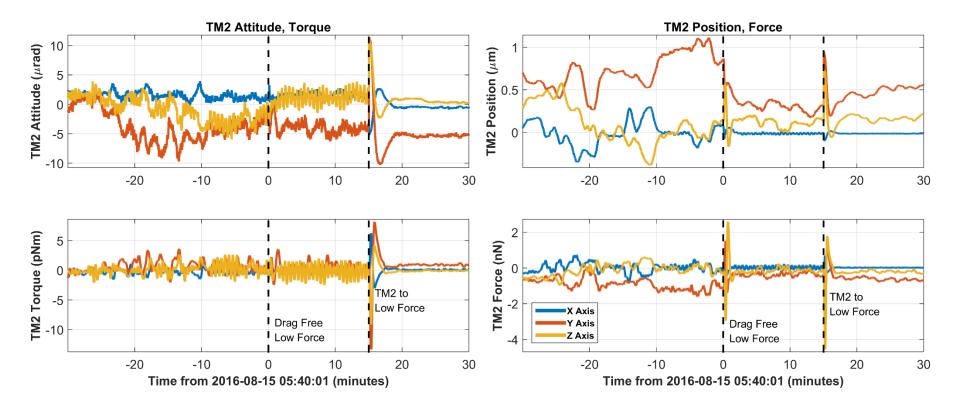
### Drag Free Low Force: Test Mass 1





## Drag Free Low Force: Test Mass 2





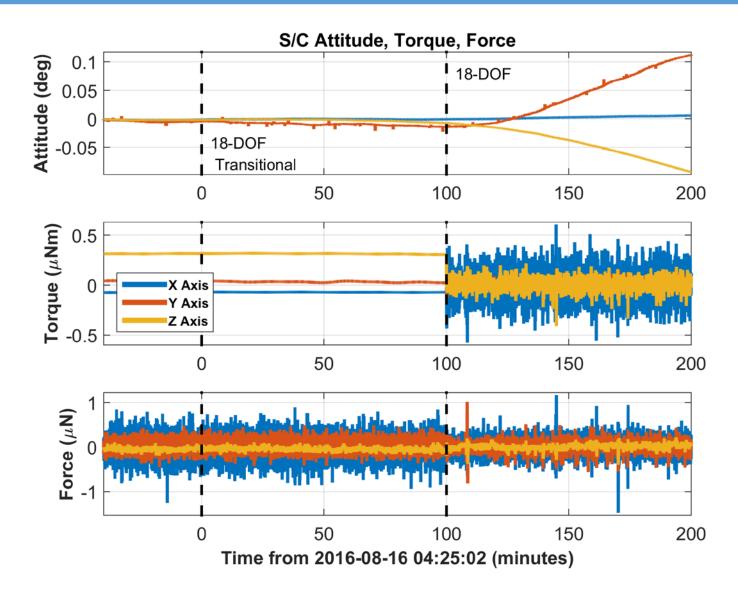
# Spacecraft/Test Mass Control Mode Design



DRS Mission Mode	Spacecraft Control Mode	Reference Test Mass Control Mode	Reference Test Mass Force Mode	Non-Reference Test Mass Control Mode	Non-Reference Test Mass Force Mode
Standby	Standby	DFS Standby	N/A	DFS Standby	N/A
Attitude Control	Attitude-Only	DFS	High Force		
Zero-G	Accelerometer	Accelerometer		DFS Accelerometer	High Force
Drag Free Low Force	Drag Free 1	DFS			
18-DOF Transitional		Drag Free 1	Low Force	Suspended Drag Free 1	Low Force
18-DOF	Science	DFS Drag Free 2		Suspended Drag Free 2	

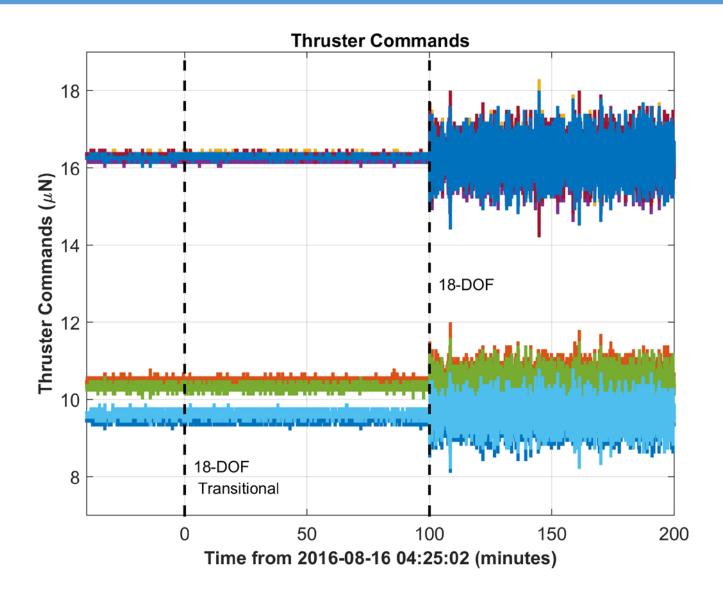
## 18-DOF: Spacecraft





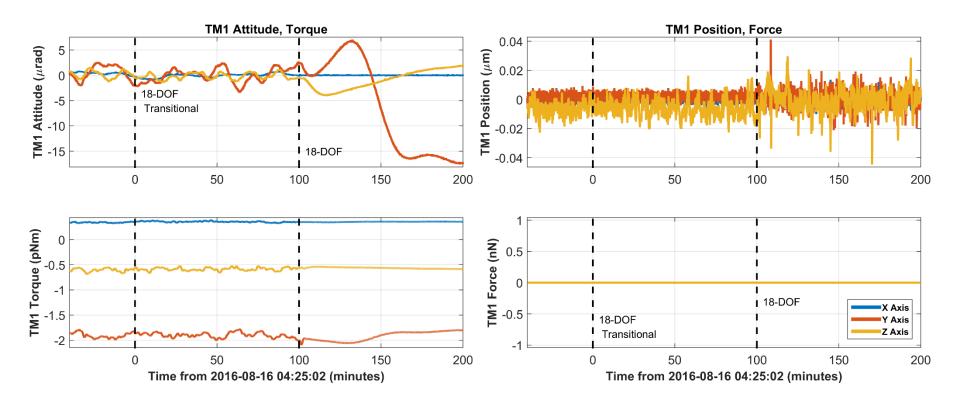
#### 18-DOF: Thruster Commands





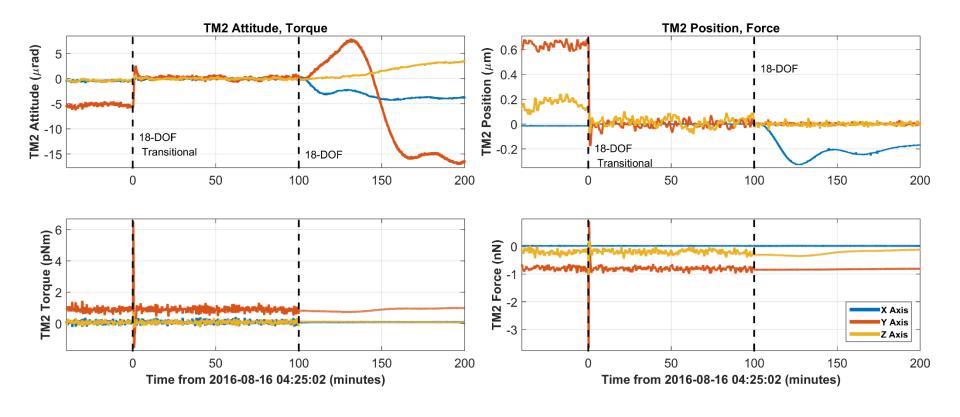
#### 18-DOF: Test Mass 1





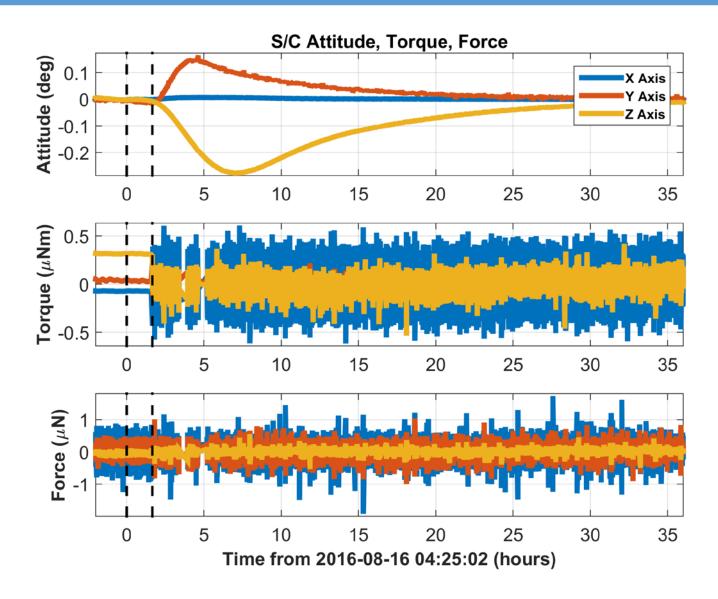
#### 18-DOF: Test Mass 2





## 18-DOF: Spacecraft





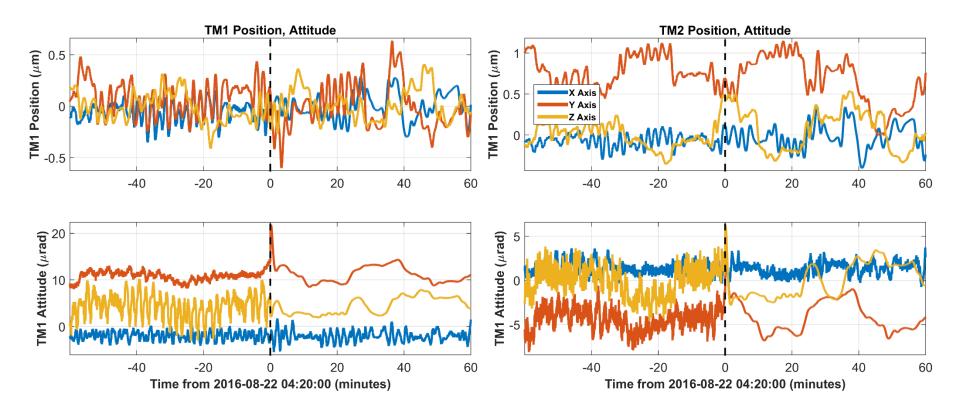
# DCS Control Mode Design



DRS Mission Mode	Spacecraft Control Mode	Reference Test Mass Control Mode	Reference Test Mass Force Mode	Non-Reference Test Mass Control Mode	Non-Reference Test Mass Force Mode
Standby	Standby	DFS Standby	N/A	DFS Standby	N/A
Attitude Control	Attitude-Only	DFS	High Force		
Zero-G	Accelerometer	Accelerometer		DFS Accelerometer	High Force
Drag Free Low Force	Drag Free 1	DFS			
18-DOF Transitional	Drag Free 1	Drag Free 1	Low Force	Suspended Drag Free 1	Low Force
18-DOF	Science	DFS Drag Free 2		Suspended Drag Free 2	

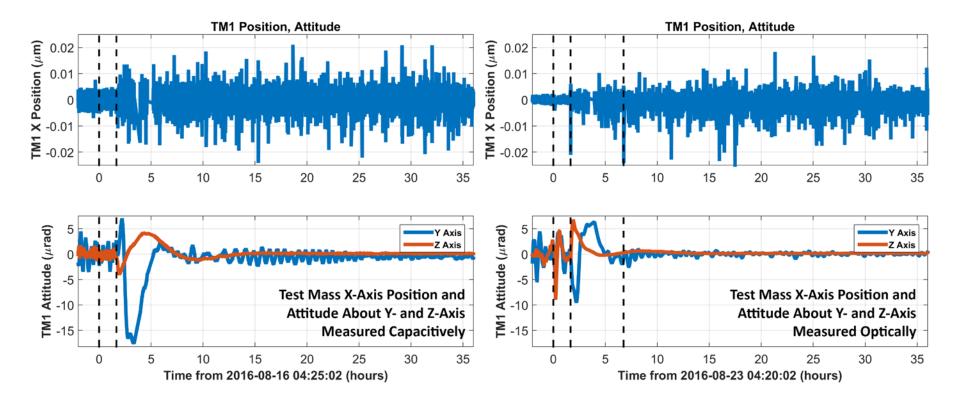
## Optical Metrology System Measurements





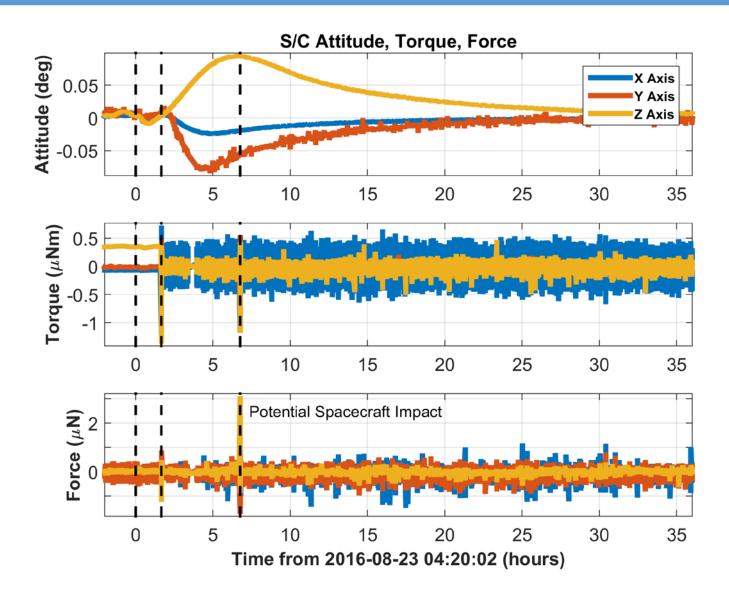
## 18-DOF w/OMS: Test Mass 1





# 18-DOF w/OMS: Spacecraft





#### Conclusion



The Disturbance Reduction System and the Dynamic Control System met all of their requirements and supported the evaluation of the performance of the Colloidal MicroNewton Thrusters. With only a few exceptions, all control modes performed nominally, with good robustness characteristics. In the few instances where there were problems, the DCS team was able to very quickly provide adjustments to control system parameters to fix them.

## Acknowledgements



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